

AMENDMENTS TO THE CLAIMS

Please amend claims 1 and 29. This listing of claims will replace all prior versions, and listings, of claims in the application.

Listing of the Claims:

CLAIMS

What is claimed is:

1. (Currently Amended) A robot, comprising:
a mobile holonomic platform;
a camera coupled to said mobile holonomic platform;
an arm that has a first linkage and a second linkage that are coupled to said mobile holonomic platform, said arm having an actuator that moves said second linkage relative to said first linkage in a first degree of freedom in a first mode, and in a second degree of freedom in a second mode; and,
a first grasper coupled to said arm.
2. (Original) The robot of claim 1, further comprising a monitor coupled to said mobile holonomic platform.
3. (Original) The robot of claim 1, wherein further comprising a shoulder actuator coupled to said arm.
4. (Original) The robot of claim 1, wherein said arm has an elbow actuator.
5. (Canceled)

6. (Original) The robot of claim 1, wherein said first grasper is coupled to a wrist joint of said arm.

7. (Original) The robot of claim 1, further comprising a second grasper coupled to said arm.

8. (Previously Presented) The robot of claim 1, wherein said first degree of freedom pivots about an elbow axis and said second degree of freedom slides relative to the elbow axis.

9. (Previously Presented) A robot, comprising:
a mobile holonomic platform;
a camera coupled to said mobile holonomic platform;
an arm coupled to said mobile holonomic platform, said arm includes a first linkage, and a second linkage coupled to said first linkage, said arm having actuator means for moving said second linkage relative to said first linkage in a first degree of freedom in a first mode, and in a second degree of freedom in a second mode; and,
first grasper means for grasping an object.

10. (Original) The robot of claim 9, further comprising a monitor coupled to said mobile holonomic platform.

11. (Original) The robot of claim 9, wherein further comprising a shoulder actuator coupled to said arm.

12. (Original) The robot of claim 9, wherein said arm has an elbow actuator.
13. (Canceled)
14. (Original) The robot of claim 9, wherein said first grasper means is coupled to a wrist joint of said arm.
15. (Original) The robot of claim 9, further comprising second grasper means for grasping the object.
16. (Previously Presented) The robot of claim 9, wherein said first degree of freedom pivots about an elbow axis and said second degree of freedom slides relative to the elbow axis.
17. (Canceled)
18. (Canceled)
19. (Canceled)
20. (Canceled)
21. (Previously Presented) A robot system, comprising:
a broadband network;
a remote station coupled to said broadband network, said remote station having a handle that can be manipulated to generate movement signals that are transmitted through said broadband network;

a robot that is coupled to said broadband network and receives said movement signals from said handle of said remote station, said robot including;

a mobile holonomic platform;

a camera coupled to said mobile holonomic platform;

an arm coupled to said mobile holonomic platform, said arm includes a first linkage, and a second linkage coupled to said first linkage, said arm further having an actuator that moves said second linkage relative to said first linkage in a first degree of freedom in a first mode, and in a second degree of freedom in a second mode in response to said movement signals; and,

a first grasper coupled to said arm.

22. (Original) The robot system of claim 21, further comprising a monitor coupled to said mobile holonomic platform.

23. (Original) The robot system of claim 21, wherein further comprising a shoulder actuator coupled to said arm.

24. (Original) The robot system of claim 21, wherein said arm has an elbow actuator.

25. (Canceled)

26. (Original) The robot system of claim 21, wherein said first grasper is coupled to a wrist joint of said arm.

27. (Original) The robot system of claim 21, further comprising a second grasper coupled to said arm.

28. (Previously Presented) The robot system of claim 21, wherein said first degree of freedom pivots about an elbow axis and said second degree of freedom slides relative to the elbow axis.

29. (Currently Amended) A robot system, comprising:
a broadband network;
input means for generating movement signals and transmitting said movement signals through said broadband network;
a robot that is coupled to said broadband network and receives said movement signals of said input means, said robot including;
a mobile holonomic platform;
a camera coupled to said mobile holonomic platform;
an arm that has a first linkage and a second linkage that are coupled to said mobile holonomic platform, said arm further having actuator means for moving said second linkage relative to said first linkage in a first degree of freedom in a first mode, and a second degree of freedom in a second mode in response to said movement signals; and,
first grasper means for grasping an object.

30. (Original) The robot system of claim 29, further comprising a monitor coupled to said mobile holonomic platform.

31. (Original) The robot system of claim 29, wherein further comprising a shoulder actuator coupled to said arm.

32. (Original) The robot system of claim 29, wherein said arm has an elbow actuator.

33. (Canceled)

34. (Original) The robot system of claim 29, wherein said first grasper means is coupled to a wrist joint of said arm.

35. (Original) The robot system of claim 29, further comprising second grasper means for grasping the object.

36. (Original) The robot system of claim ~~33~~29, wherein said first degree of freedom pivots about an elbow axis and said second degree of freedom slides relative to the elbow axis.

37. (Canceled)

38. (Canceled)

39. (Canceled)

40. (Canceled)